DESCRIPTIVE ABSTRACT

A remote manipulation arm comprises a master arm (5) mechanically separated from the slave arm (1), the link being re-established by an interface system (6) comprising a control portion (7) and a mechanical portion (8) for driving the slave arm. According to the invention, the mechanical portion (8) comprises a stationary motor and a transmission capable of rotating a tubular segment (3) passing through the slave arm by at least a full turn to increase the work space.

Fig. 1.